

ABSTRACT

To break up high surface tension forces between an amorphous lens mold and a hydrated lens, a precise x-and-y-coordinate motion tangential to the lens surface is used in combination with a z-coordinate motion using the vacuum of a lens pick and place robot. The sequence of motions permits the transfer of lenses in an automated fashion from the molding step to a subsequent process in a robust and accurate manner, thereby minimizing lens-handling defects.